

FIG.1

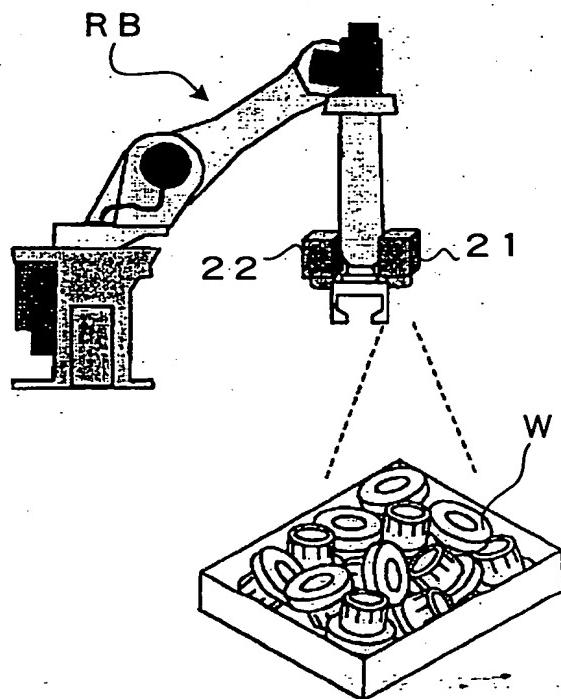


FIG. 2a

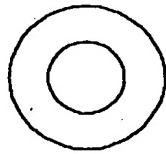


FIG. 2b

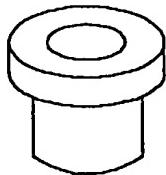


FIG. 2c

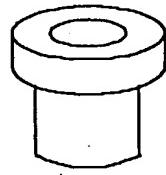
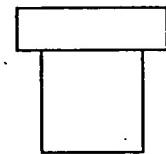
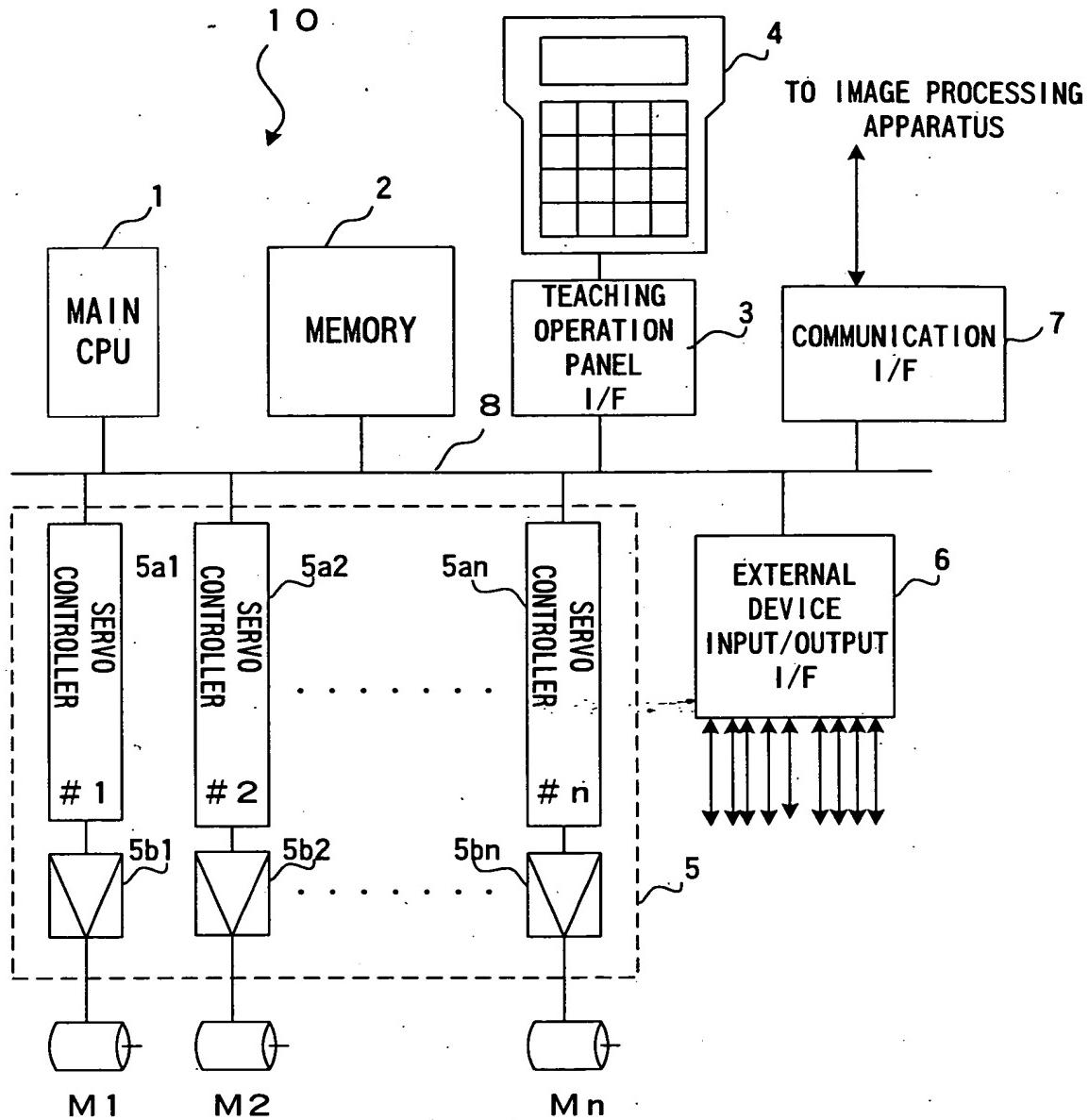


FIG. 2d



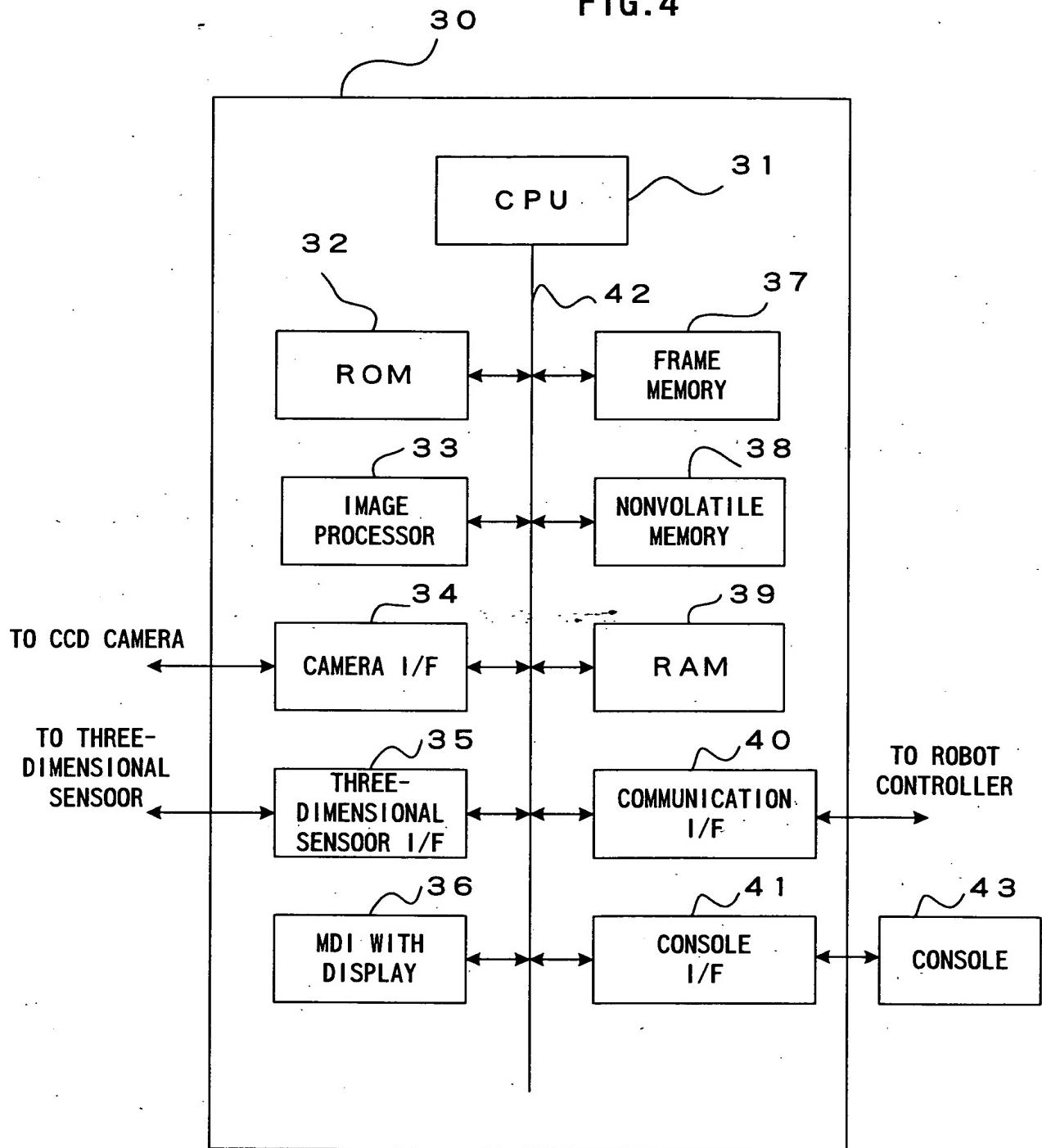
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FIG.3



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FIG.4



00000000000000000000000000000000

FIG.5

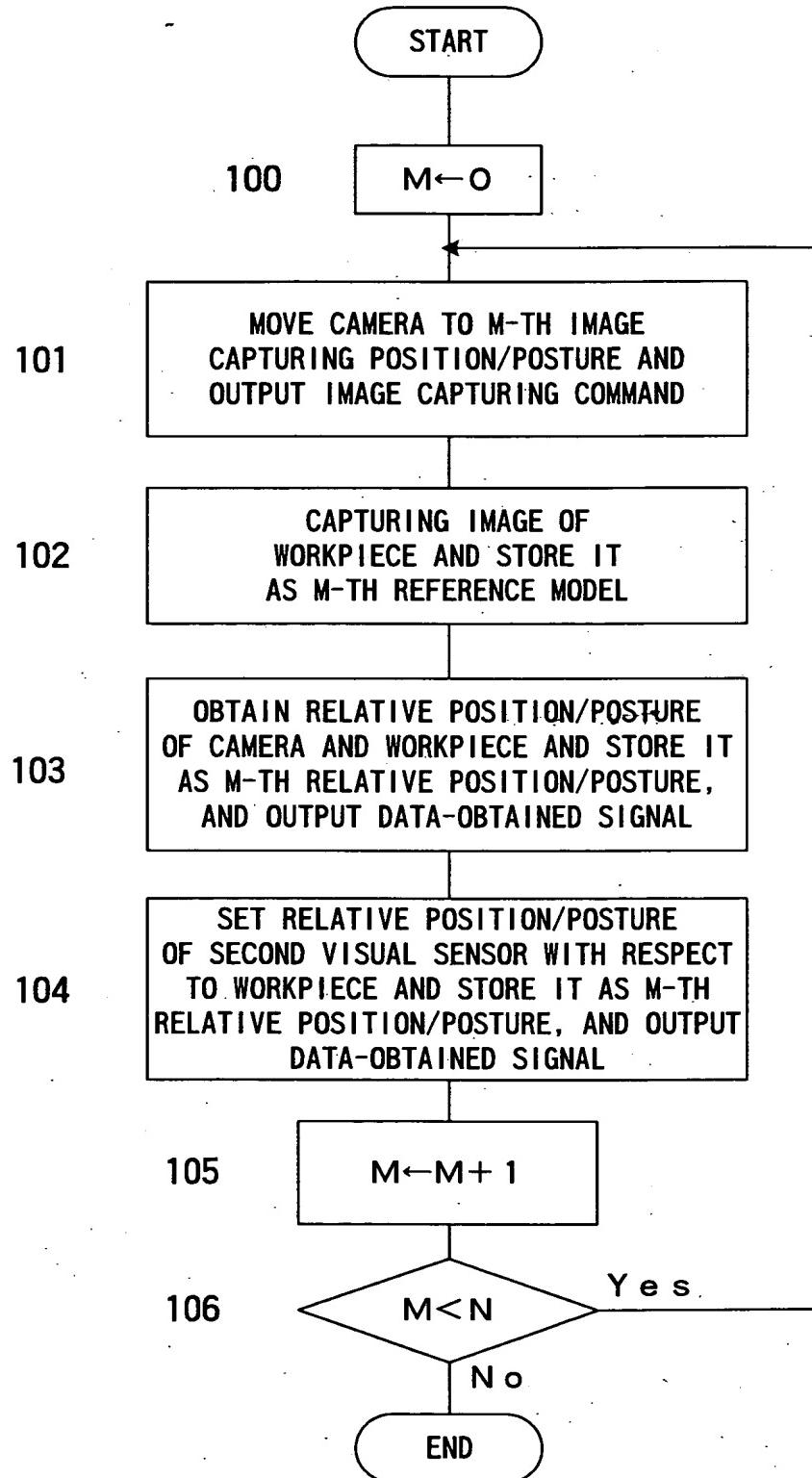
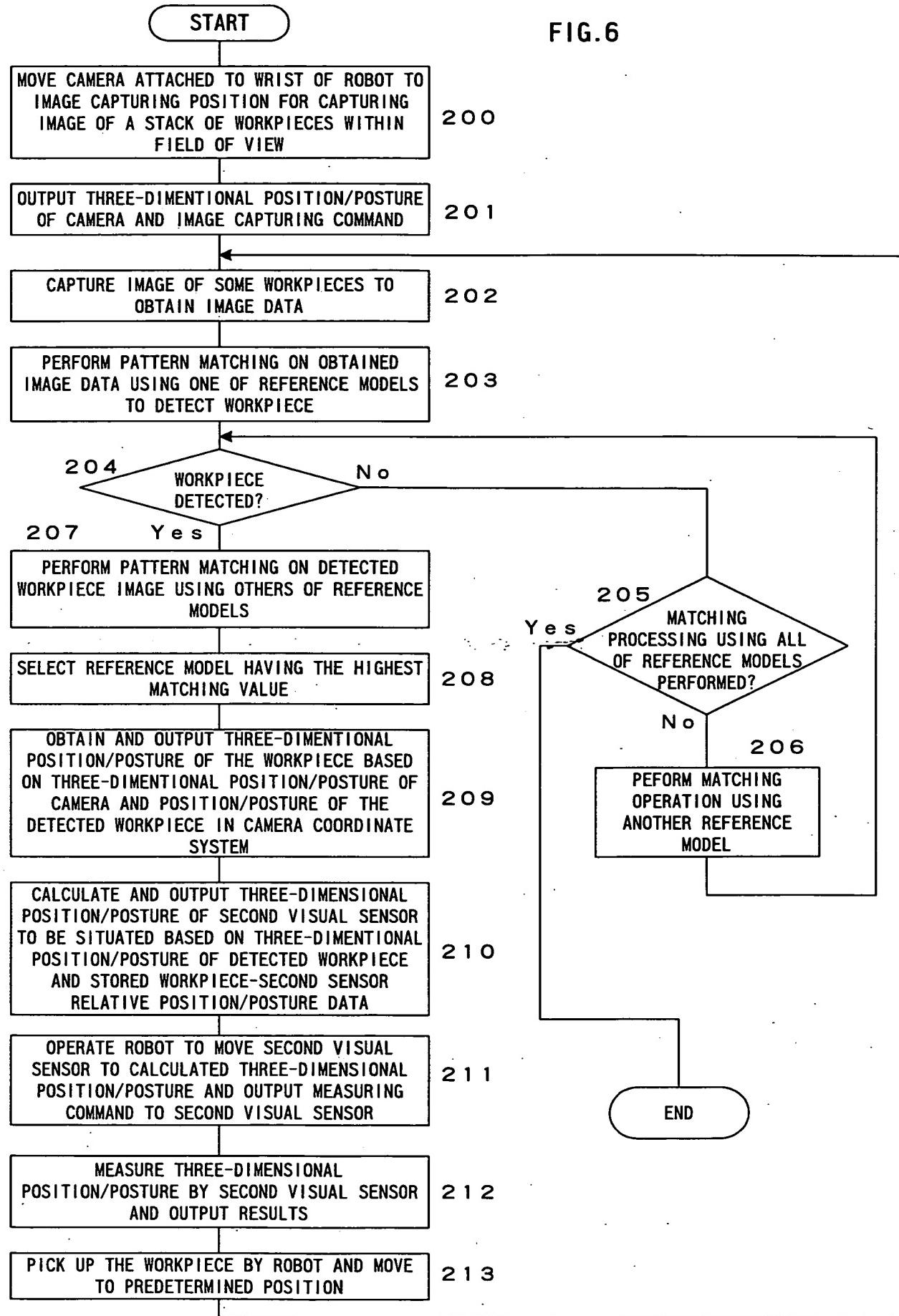


FIG.6

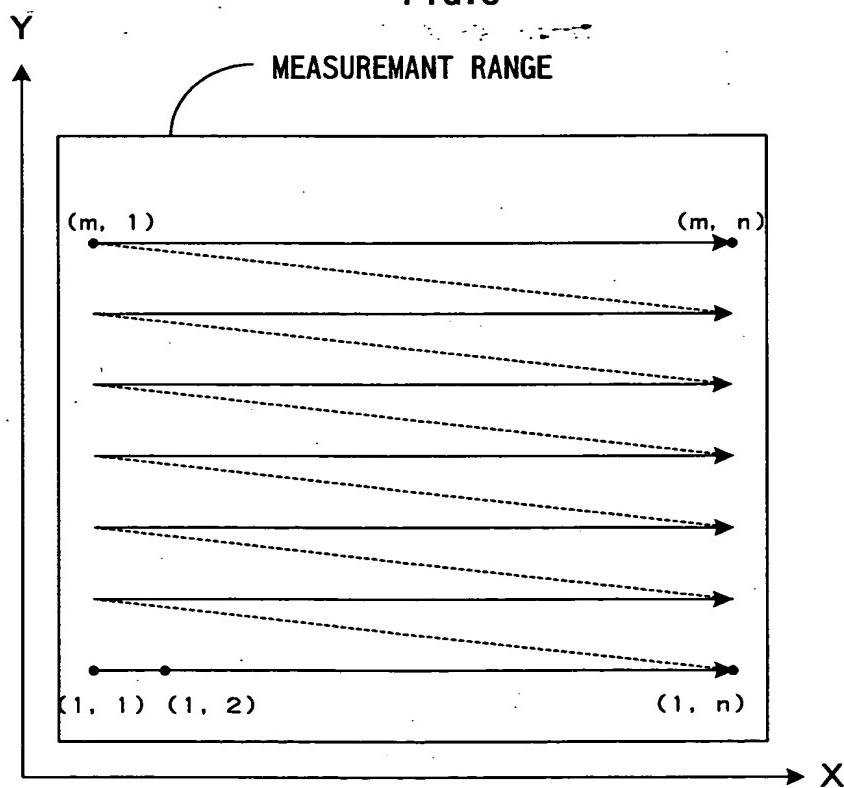


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FIG.7

REFERENCE MODEL NO. (M)	FIRST-SENSOR RELATIVE POSITION/POSTURE [RELATIVE POSITION POSTURE OF WORKPIECE WITH RESPECT TO CAMERA] (X, Y, Z, α , β , γ) c	WORKPIECE-ROBOT RELATIVE POSITION/POSTURE [RELATIVE POSITION POSTURE OF SECOND VISUAL SENSOR TO BE SITUATED WITH RESPECT TO WORKPIECE] (X, Y, Z, α , β , γ) wk
0	10.0, -20.8, 50.5, 0.0, 0.0, 0.0	35.5, 20.5, 60.9, 0.0, 0.0, 0.0
1	10.0, -20.8, 50.5, 30.0, 0.0, 0.0	35.5, 20.5, 60.9, 0.0, 0.0, 0.0
2	10.0, -20.8, 50.5, 60.0, 0.0, 0.0	35.5, 20.5, 60.9, 0.0, 0.0, 0.0
3	10.0, -20.8, 50.5, 90.0, 0.0, 0.0	35.5, 20.5, 60.9, 0.0, 0.0, 0.0

FIG.8



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FIG.9

$Z(m,1)$	· · ·	· · ·	· · ·	· · ·	$Z(m,n)$
· · ·	· · ·	· · ·	· · ·	· · ·	· · ·
· · ·	· · ·	· · ·	· · ·	· · ·	· · ·
· · ·	· · ·	$Z(i,j)$	· · ·	· · ·	· · ·
· · ·	· · ·	· · ·	· · ·	· · ·	· · ·
$Z(1,1)$	$Z(1,2)$	· · ·	· · ·	· · ·	$Z(1,n)$

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FIG.10

